

Abstract

The parameterization information needed in a universal motion controller UMC (description of system variables, alarms, and commands) is generated from a uniform description language via a central converter (U) and distributed to the engineering system (ES1-ES4), run time system (RTS1-RTS4), and output media (AM) for documentation. This ensures the consistency of parameterization data for all system parts. In addition, configuration information (FWK) from technology packets (TP) can be imported into the engineering (ES1-ES4) and run time RTS1-RTS4) systems of the controller.